

In the Claims:

Please amend the claims as follows:

1. (currently amended) A system including at least two manipulators ~~namely robots and/or external axes~~, each ~~manipulator controlled by a control system and~~ programmed to carry out a plurality of tasks, the system comprising,

a handheld control tool for manually manipulating the manipulators, said handheld control tool comprising a communication means communicating unit configured to communicate with the control system, wherein each manipulator is movably oriented in a first coordinate system, ~~and wherein~~ a second coordinate system is defined for each manipulator so that one part of each said manipulator stands still in the second coordinate system, and wherein each second coordinate system is movable relative to the first coordinate system, ~~and the system is adapted to:~~

a controller configured to control the manipulators such that the manipulators move together in a synchronized motion when one of the manipulators is moved, wherein the control system is configured to select one of said manipulators as a leading manipulator, create a memory list including all remaining manipulators that are to be moved synchronously with the leading manipulator, receive a movement command from the handheld control tool, create a move order for the leading manipulator, based on the received movement command ~~and the~~ a current position of the leading manipulator, and create move orders for the remaining manipulators in the memory list, such that ~~said~~ parts of the manipulators, which stand still in the second coordinate systems, are moved such that ~~they keep their relative~~ the parts maintain positions relative to the second coordinate system of the leading manipulator.

2. (currently amended) The system according to claim 1, wherein said hand held control tool comprises a manipulator input ~~means in a form of~~ member comprising a joystick.

3. (currently amended) A method for controlling a system of manipulators including at least two manipulators, ~~namely robots and/or external axes~~, each ~~manipulator~~ controlled by a control system and programmed to carry out a plurality of tasks, wherein each manipulator is movably oriented in a first coordinate system, the system comprising a handheld control tool for manually manipulating the manipulators, said hand held control tool comprising a communication ~~means communicating~~ unit configured to communicate with the control system, ~~wherein~~ the method ~~comprises~~ comprising:

defining a second coordinate system for each manipulator so that one part of said manipulator stands still in the second coordinate system, ~~and that~~ wherein each second coordinate system is movable relative to the first coordinate system,

selecting one of said manipulators as a leading manipulator,

creating a memory list including all manipulators that are to be moved synchronously with the leading manipulator,

receiving a movement command from the hand held control tool,

creating a move order for the leading manipulator, based on the received movement command and ~~the~~ a current position of the leading manipulator, and

creating move orders for the remaining manipulators in the memory list, such that ~~said~~ parts of the manipulators, which stand still in the second coordinate systems, are moved such that ~~they keep their relative~~ the parts maintain positions relative to the second coordinate system of

the leading manipulator, thereby controlling the manipulators such that the manipulators move together in a synchronized motion when one of the manipulators is moved.

4. (currently amended) The method according to claim 3, wherein said hand held control tool comprises a manipulator input ~~means in a form of~~ member comprising a joystick creating a movement command by using the joystick.

5. (new) The method according to claim 3, wherein the at least two manipulators comprise at least one of robots or external axes.

6. (new) The system according to claim 1, wherein the at least two manipulators comprise at least one of robots or external axes.